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ABSTRACT

A robotic system has been designed that can be used as a minimally invasive surgical device. The system has a master end and a slave end. The master end has five physical movements corresponding to physical movements at the slave end with five degrees of freedom. 5 There is force feedback from the slave end to the master end for each physical movement. The interface can be one or more computers. The master end can be remote from the slave end and the slave end can be a surgical robot or a simulation program on a computer.